

IN THE SPECIFICATION

Revise the paragraph beginning on line 2 of page 21 as follows:

-- Fig.15 is a perspective view ~~showing~~ showing an illustrative structure of a relative movement measurement sensor capable of measuring the relative movement around a normal line drawn from the road surface of the foot sole.--

Revise the paragraph beginning on line 8 of page 25 as follows:

-- In actuality, the above-described respective degrees of freedom of the legged mobile robot 100 are realized as ~~asetive~~ active movements by joint actuators. From a variety of requirements for eliminating any excess bulging portions in the appearance of the overall device to simulate the shape of the body of the human being, and for exercising orientation control on an unstable structure for realizing walking on two feet, the joint actuators are desirably small-sized and lightweight.--

Revise the paragraph beginning on line 21 of page 36 as follows:

--The relative movement measurement sensor 1104, shown in Figs.12 and 13, calculate the amounts of relative movements of the foot with respect to a surface parallel to the road surface, that is amounts of relative movements (slip) X and Y in the X-axis direction (roll axis direction) and in the Y-axis direction (pitch axis direction). However, the ~~asmeunts~~ amount of relative movement around a normal of the road surface, as well as the amount of relative movement in the direction parallel to the road surface, is crucial in movement control or trajectory correction of the legged mobile robot 100, as discussed above. The relative movement

measurement sensor, capable of measuring the amount of relative movement (slip) around the normal line from the road surface, is hereinafter explained.--